

## **AMENDMENTS TO THE CLAIMS**

This listing of claims will replace all prior versions, and listings, of claims in the application:

### **Listing of Claims**

**Claim 1 (Currently amended):** An industrial robot comprising:  
a base for installation,  
a swing part swinging with respect to said base,  
a first arm swinging together with said swing part with respect to said base and rotating with respect to said swing part, and

a second arm swinging together with said swing part with respect to said base and rotating with respect to said first arm,

wherein said first arm is curved in the rotating direction with respect to ~~the said~~ swing part, ~~the first arm having a continuous-curved C shape, wherein a thickness of said C-shaped first arm decreases continuously from one end connected to the first drive part to the other end connected to a second arm drive part.~~

**Claim 2 (Currently amended):** The industrial robot according to claim 1, wherein said first arm is curved in a direction opposite to the interior angle formed by said first arm and said second arm.

**Claim 3 (Currently amended):** An industrial robot comprising:

a base for installation,  
a swing part swinging with respect to said base,  
a first arm swinging together with said swing part with respect to said base and rotating with respect to said swing part, and

a second arm swinging together with said swing part with respect to said base and rotating with respect to said first arm, wherein [[a]] ~~the~~ center of gravity of said first arm is offset with respect to a line segment connecting the first arm rotating axis with respect to said swing part and the second arm rotating axis with respect to said first arm,

the first arm having a continuous-curved C shape, wherein a thickness of said C-shaped first arm decreases continuously from one end connected to the first drive part to the other end connected to a second arm drive part.

**Claim 4 (Original):** The industrial robot according to claim 3, wherein the center of gravity of said first arm is positioned in a direction opposite to the interior angle formed by said first arm and said second arm.